

CLAIMS

1. An impact absorbing mechanism for a walking robot, the impact absorbing mechanism provided to a foot of an extremity of each of a plurality of movable legs of the walking robot having the movable legs, comprising:

5 an upper base plate joined to a foot joint of each of the movable legs;

a lower base plate positioned below the upper base plate, and being opposite to the upper base plate; and

at least three elastic members anisotropic in terms of elasticity,
10 which are arranged at equal intervals in a circumferential direction about a predetermined axis line extending in a direction perpendicular to the upper base plate, between the upper base plate and the lower base plate, each of which allows the lower base plate to make elastic displacement relative to the upper base plate in the same direction as
15 the predetermined axis direction extends, while each of which inhibits the lower base plate from making elastic displacement relative to the upper base plate in directions orthogonal to the predetermined axis direction, and which join the upper base plate and the lower base plate elastically.

20 2. The impact absorbing mechanism for a walking robot according to claim 1, comprising:

at least three high damping members which are arranged at equal intervals in a circumferential direction about the predetermined axis line, between the upper base plate and the lower base plate, and which
25 damp vibration of the lower base plate relative to the upper base plate.